

**AMENDMENTS TO THE CLAIMS:**

This listing of claims will replace all prior versions and listings of claims in the application:

1. (Original) An articulated robot comprising a plurality of joint arms connected to one another, wherein the joint arms are connected to one another via a first rotating shaft at at least one location and via a second rotating shaft at at least one location, the axis of the second rotating shaft being inclined relative to the axis of the first rotating shaft, and wherein each rotating shaft is provided with a motor for driving the rotating shaft and with a speed-reducing mechanism.
2. (Original) The articulated robot according to claim 1, wherein each of the first and second rotating shafts has a hollow part through which a cable or the like necessary for controlling the articulated robot is passed.
3. (Withdrawn) The articulated robot according to claim 1 or 2, wherein each joint arm is provided with a motor for driving either the first or the second rotating shaft connected thereto.
4. (Original) The articulated robot according to claim 1 or 2, wherein the plurality of joint arms comprises joint arms having the first rotating shaft on one end and the second rotating shaft on the other end, wherein, among the joint arms with the first and second rotating shafts, joint arms having two motors for driving the first and second rotating shafts and joint arms with no motor are alternately connected.

5. (Withdrawn) The articulated robot according to claim 1, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

6. (Withdrawn) The articulated robot according to claim 2, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

7. (Withdrawn) The articulated robot according to claim 3, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

8. (Withdrawn) The articulated robot according to claim 4, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.